Amendments to the Specification:

Please amend the specification as follows:

Page 1: After the title, insert:

--INCORPORATION BY REFERENCE

This is a 371 national phase application of PCT/IB04/04048 filed 09 December 2004, claiming priority to Japanese Patent Application No. 2003-425109 filed 22 December 2003, the contents of which are incorporated herein by reference.—

Pages 3-4: Replace paragraphs **[0008]** and **[0009]** with the following amended paragraphs:

[0008]   In view of the above, ~~it is an object of the invention to provide~~ a constant velocity universal joint in which a thrust force generated during rotation can be suppressed <u>is provided</u>.

[0009]   An aspect of the invention relates to a constant velocity universal joint including (a) a hollow outer joint member in which plural guide grooves extending in an axial direction of the outer joint member are formed in a<u>n</u> inner peripheral surface in an axial direction, and which is connected to a first shaft; (b) an inner joint member which is connected to a second shaft, and which is housed in the outer joint member; (c) plural leg shafts provided in the inner joint member, each of which protrudes in a radial direction of the second shaft, and in each of which a convex sphere is formed in a tip portion; [[and]] (d) ~~a roller unit including~~ an inner roller in which a concave sphere that is engaged with the convex sphere of each of the leg shafts is formed in an inner peripheral surface, [[and]] <u>(e)</u> an outer roller which is housed in each of the guide grooves of the outer joint member so as to be slidable, <u>(f) a rolling body which is provided between</u> the inner roller and the outer roller ~~being~~ <u>so that the inner roller and the outer roller are</u> movable with respect to each other in an axial direction of the inner roller and the outer roller ~~through a rolling body~~, wherein each of the leg shafts and the inner

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roller can be oscillated with respect to each other, wherein [[(e)]] (g) the leg shafts and the inner roller can be oscillated with respect to each other. The constant velocity universal joint is characterized in that [[(f)]] (h) a cylindrical surface is formed in a radially outer surface of the outer roller; [[(g)]] (i) a flat engagement surface which is engaged with the cylindrical surface of the outer roller is formed in a lateral surface of each of the guide grooves of the outer joint member; and [[(h)]] (j) the cylindrical surface of the outer roller satisfies the following two equations.

(equation 3) $W1 > PCR(1 - \cos\theta)/2 + \mu_3 R_3 + \mu_2 R1$

(equation 4) $W2 > 3PCR(1 - \cos\theta)/2 - \mu_3 R_3 + \mu_2 R1$

In these equations, W1 indicates a length in an axial direction of the cylindrical surface from a center of the cylindrical surface in the axial direction to an end portion of the cylindrical surface on an outer peripheral side of the outer joint member, W2 indicates a length in the axial direction of the cylindrical surface from the center of the cylindrical surface in the axial direction to an end portion of the cylindrical surface on a joint center side of the outer joint member, PCR indicates a distance from an axis of the inner joint member to a center of the convex sphere of each of the leg shafts, θ indicates a required maximum joint angle, R1 indicates a radius of the cylindrical surface of the outer roller, R_3 indicates a radius of the concave sphere of the inner roller, μ_2 indicates a friction coefficient when the inner roller is moved with respect to the outer roller in an axial direction of the inner roller [[(16)]], and μ_3 indicates a friction coefficient between the convex sphere of each of the leg shafts and the concave sphere of the inner roller.